

Abstract

When an angular acceleration α of a rotating shaft of a motor connected with a drive shaft exceeds a preset threshold value α_{slip} , which suggests the occurrence of a skid, the torque control procedure sets a maximum torque T_{max} by referring to a map, which gives a smaller maximum torque T_{max} with an increase in angular acceleration α , and restricts the motor torque to the maximum torque T_{max} . The maximum torque T_{max} is fixed to a value corresponding to a peak value of the angular acceleration α at the time of occurrence of a skid. The torque control procedure then integrates the angular acceleration α to give a time integration thereof over an integration interval when the angular acceleration α once exceeds the preset threshold value α_{slip} and decreases again below the preset threshold value α_{slip} by the motor torque restriction. When the motor torque restriction practically converges the skid, the torque restricted to the maximum torque T_{max} corresponding to the peak value of the angular acceleration α is restored to the new setting of the maximum torque T_{max} corresponding to the time integration of the angular acceleration α .